

Contents

1	Introduction	1
1.1	History	3
1.2	Geometry	5
1.3	Outlook	6
1.4	Overview of This Text	8
1.4.1	CLUCALC	9
1.4.2	Algebra	9
1.4.3	Geometries	10
1.4.4	Numerics	10
1.4.5	Uncertain Geometric Entities and Operators	13
1.4.6	The Inversion Camera Model	13
1.4.7	Monocular Pose Estimation	14
1.4.8	Versor Functions	14
1.4.9	Random Variable Space	15
1.5	Overview of Geometric Algebra	15
1.5.1	Basics of the Algebra	16
1.5.2	General Vectors	17
1.5.3	Geometry	19
1.5.4	Transformations	21
1.5.5	Outermorphism	23
2	Learning Geometric Algebra with CLUCalc	25
2.1	Background	26
2.2	The Software	27
2.2.1	Editor Window	28
2.2.2	Visualization Window	29
2.2.3	Output Window	29
2.2.4	Command Line Parameters	30
2.3	The Scripting Language	30
2.3.1	Basics	30
2.3.2	Visualizing Geometry	32

2.3.3	User Interaction	39
2.3.4	Animation	40
2.3.5	Annotating Graphics	42
2.3.6	Multivector Calculations	45
2.4	Summary	48

Part I Theory

3	Algebra	51
3.1	Basics	52
3.1.1	Axioms	52
3.1.2	Basic Properties	54
3.1.3	Algebraic Basis	56
3.1.4	Involutions	59
3.1.5	Duality	60
3.1.6	Inner and Outer Product	61
3.2	Blades	64
3.2.1	Geometric Product	64
3.2.2	Outer Product	66
3.2.3	Scalar Product	68
3.2.4	Reverse	69
3.2.5	Conjugate	69
3.2.6	Norm	70
3.2.7	Inner Product	72
3.2.8	Duality	79
3.2.9	Inverse	81
3.2.10	Projection	82
3.2.11	Rejection	83
3.2.12	Meet and Join	84
3.2.13	Regressive Product	89
3.3	Versors	89
3.3.1	Definitions	90
3.3.2	Properties	91
3.4	Linear Functions	93
3.4.1	Determinant	94
3.4.2	Determinant Product	96
3.4.3	Inverse	96
3.4.4	Summary	96
3.5	Reciprocal Bases	97
3.5.1	Definition	98
3.5.2	Example	98
3.6	Differentiation	99
3.6.1	Vector Derivative	99
3.6.2	Multivector Differentiation	101
3.6.3	Tensor Representation	103

3.7	Algorithms	104
3.7.1	Basis Orthogonalization	105
3.7.2	Factorization of Blades	105
3.7.3	Evaluation of the Join	106
3.7.4	Versor Factorization	107
3.8	Related Algebras	109
3.8.1	Gibbs's Vector Algebra	109
3.8.2	Complex Numbers	110
3.8.3	Quaternions	111
3.8.4	Grassmann Algebra	114
3.8.5	Grassmann–Cayley Algebra	115
4	Geometries	119
4.1	Euclidean Space	121
4.1.1	Outer-Product Representations	122
4.1.2	Geometric Interpretation of the Inner Product	123
4.1.3	Inner Product Representation	124
4.1.4	Reflections	127
4.1.5	Rotations	130
4.1.6	Mean Rotor	133
4.2	Projective Space	134
4.2.1	Definition	134
4.2.2	Outer-Product Representations	138
4.2.3	Inner-Product Representations	140
4.2.4	Reflections in Projective Space	142
4.2.5	Rotations in Projective Space	143
4.3	Conformal Space	145
4.3.1	Stereographic Embedding of Euclidean Space	146
4.3.2	Homogenization of Stereographic Embedding	147
4.3.3	Geometric Algebra on $\mathbb{R}^{n+1,1}$	150
4.3.4	Inner-Product Representations in $\mathbb{G}_{4,1}$	152
4.3.5	Outer-Product Representations in $\mathbb{G}_{4,1}$	158
4.3.6	Summary of Representations	161
4.3.7	Stratification of Spaces	161
4.3.8	Reflections in $\mathbb{G}_{n+1,1}$	163
4.3.9	Inversions in $\mathbb{G}_{n+1,1}$	164
4.3.10	Translations in $\mathbb{G}_{n+1,1}$	168
4.3.11	Rotations in $\mathbb{G}_{n+1,1}$	170
4.3.12	Dilations in $\mathbb{G}_{n+1,1}$	171
4.3.13	Summary of Operator Representations	172
4.3.14	Incidence Relations	173
4.3.15	Analysis of Blades	176
4.4	Conic Space	179
4.4.1	Polynomial Embedding	180
4.4.2	Symmetric-Matrix Vector Space	181

4.4.3	The Geometric Algebra \mathbb{G}_6	183
4.4.4	Rotation Operator	184
4.4.5	Analysis of Conics	186
4.4.6	Intersecting Lines and Conics	189
4.4.7	Intersection of Conics	190
4.5	Conformal Conic Space	193
4.5.1	The Vector Space	193
4.5.2	The Geometric Algebra $\mathbb{G}_{5,3}$	194
5	Numerics	197
5.1	Tensor Representation	198
5.1.1	Component Vectors	199
5.1.2	Example: Geometric Product in \mathbb{G}_2	200
5.1.3	Subspace Projection	201
5.1.4	Example: Reduced Geometric Product	202
5.1.5	Change of Basis	203
5.2	Solving Linear Geometric Algebra Equations	203
5.2.1	Inverse of a Multivector	204
5.2.2	Versor Equation	205
5.2.3	Example: Inverse of a Multivector in \mathbb{G}_2	207
5.3	Random Multivectors	208
5.3.1	Definition	208
5.3.2	First-Order Error Propagation	210
5.3.3	Bilinear Functions	212
5.3.4	Summary	214
5.4	Validity of Error Propagation	215
5.4.1	Non-Gaussivity	215
5.4.2	Error Propagation Bias	217
5.4.3	Conclusions	220
5.5	Uncertainty in Projective Space	221
5.5.1	Mapping	221
5.5.2	Random Homogeneous Vectors	223
5.5.3	Conditioning	224
5.6	Uncertainty in Conformal Space	228
5.6.1	Blades and Operators	230
5.7	Uncertainty in Conic Space	233
5.8	The Gauss–Markov Model	234
5.8.1	Linearization	235
5.8.2	Constraints on Parameters Alone	236
5.8.3	Least-Squares Estimation	236
5.8.4	Numerical Calculation	238
5.8.5	Generalization	238
5.9	The Gauss–Helmert Model	239
5.9.1	The Constraints	239
5.9.2	Least-Squares Minimization	242

5.9.3	Derivation of the Covariance Matrix $\Sigma_{\Delta p, \Delta p}$	244
5.9.4	Numerical Evaluation	246
5.9.5	Generalization	248
5.10	Applying the Gauss–Markov and Gauss–Helmert Models	248
5.10.1	Iterative Application of Gauss–Helmert Method	249

Part II Applications

6	Uncertain Geometric Entities and Operators	255
6.1	Construction	255
6.1.1	Geometric Entities in Conformal Space	256
6.1.2	Geometric Entities in Conic Space	258
6.1.3	Operators in Conformal Space	259
6.2	Estimation	263
6.2.1	Estimation of Geometric Entities	263
6.2.2	Versor Equation	265
6.2.3	Projective Versor Equation	267
6.2.4	Constraint Metrics	268
6.2.5	Estimation of a 3D Circle	272
6.2.6	Estimation of a General Rotor	274
6.3	Hypothesis Testing	275
7	The Inversion Camera Model	277
7.1	The Pinhole Camera Model	279
7.2	Definition of the Inversion Camera Model	281
7.3	From Pinhole to Lens	282
7.3.1	Mathematical Formulation	283
7.3.2	Relationship Between Focal Length and Lens Distortion	288
7.4	Fisheye Lenses	293
7.5	Catadioptric Camera	294
7.6	Extensions	296
8	Monocular Pose Estimation	299
8.1	Initial Pose	301
8.2	Formulation of the Problem in CGA	305
8.3	Solution Method	307
8.3.1	Tensor Form	308
8.3.2	Jacobi Matrices	310
8.3.3	Constraints on Parameters	311
8.3.4	Iterative Estimation	313
8.4	Experiments	316
8.4.1	Setup	317
8.4.2	Execution	320
8.4.3	Results	321
8.5	Conclusions	322

9	Versor Functions	325
9.1	Coupled Motors	326
9.1.1	Cycloidal Curves	326
9.1.2	Fourier Series	327
9.1.3	Space Curves	330
9.2	Pythagorean-Hodograph Curves	330
9.2.1	Relation to Versor Equation	332
9.2.2	Pythagorean-Hodograph Curves	333
9.2.3	Relation Between the Rotation and Reflection Forms .	336
9.2.4	Pythagorean-Hodograph Quintic Hermite Interpolation	339
9.2.5	Degrees of Freedom	340
9.2.6	Curves of Constant Length	342
9.2.7	Pythagorean-Hodograph Curves in \mathbb{R}^n	347
9.2.8	Summary	347
9.2.9	Proof of Lemma 9.5	348
10	Random-Variable Space	351
10.1	A Random-Variable Vector Space	352
10.1.1	Probability Space	352
10.1.2	Continuous Random Variables	352
10.1.3	Multiple Random Variables	354
10.2	A Hilbert Space of Random Variables	356
10.2.1	The Norm	356
10.2.2	The Scalar Product	357
10.2.3	The Dirac Delta Distribution	358
10.3	Geometric Algebra over Random Variables	360
10.3.1	The Norm	361
10.3.2	General Properties	362
10.3.3	Correlation	363
10.3.4	Normal Random Variables	365
	Notation	369
	References	371
	Index	381